

Document made available under the Patent Cooperation Treaty (PCT)

International application number: PCT/EP05/002303

International filing date: 04 March 2005 (04.03.2005)

Document type: Certified copy of priority document

Document details: Country/Office: EP
Number: 04005458.7
Filing date: 08 March 2004 (08.03.2004)

Date of receipt at the International Bureau: 07 April 2005 (07.04.2005)

Remark: Priority document submitted or transmitted to the International Bureau in compliance with Rule 17.1(a) or (b)



World Intellectual Property Organization (WIPO) - Geneva, Switzerland
Organisation Mondiale de la Propriété Intellectuelle (OMPI) - Genève, Suisse



Europäisches
Patentamt

European
Patent Office

Office européen
des brevets

EP05/02303

Bescheinigung

Certificate

Attestation

Die angehefteten Unterlagen stimmen mit der ursprünglich eingereichten Fassung der auf dem nächsten Blatt bezeichneten europäischen Patentanmeldung überein.

The attached documents are exact copies of the European patent application described on the following page, as originally filed.

Les documents fixés à cette attestation sont conformes à la version initialement déposée de la demande de brevet européen spécifiée à la page suivante.

Patentanmeldung Nr. Patent application No. Demande de brevet n°

04005458.7

Der Präsident des Europäischen Patentamts;
Im Auftrag

For the President of the European Patent Office

Le Président de l'Office européen des brevets
p.o.

R C van Dijk



Anmeldung Nr:
Application no.: 04005458.7
Demande no:

Anmeldetag:
Date of filing: 08.03.04
Date de dépôt:

Anmelder/Applicant(s)/Demandeur(s):

sd&m Software design & management AG
Carl-Wery-Strasse 42
81739 München
ALLEMAGNE

Bezeichnung der Erfindung/Title of the invention/Titre de l'invention:
(Falls die Bezeichnung der Erfindung nicht angegeben ist, siehe Beschreibung.
If no title is shown please refer to the description.
Si aucun titre n'est indiqué se référer à la description.)

Determining and using geometric feature data

In Anspruch genommene Priorität(en) / Priority(ies) claimed /Priorité(s)
revendiquée(s)
Staat/Tag/Aktenzeichen/State/Date/File no./Pays/Date/Numéro de dépôt:

Internationale Patentklassifikation/International Patent Classification/
Classification internationale des brevets:

G06T/

Am Anmeldetag benannte Vertragsstaaten/Contracting states designated at date of
filing/Etats contractants désignées lors du dépôt:

AT BE BG CH CY CZ DE DK EE ES FI FR GB GR HU IE IT LU MC NL
PL PT RO SE SI SK TR LI

08. März 2004

Determining and Using Geometric Feature Data

The present invention generally concerns the technical field of the computer-based processing of objects that have different shapes and different geometrical features. More particularly, the present invention concerns the field of determining and using feature data that represents information about the shape of an object. The teaching of the present invention can be employed in a variety of applications including, but not limited to, the similarity search and classification on protein, CAD, and web data.

In the last ten years, an increasing number of database applications has emerged for which efficient and effective support for similarity search is essential. The importance of similarity search and classification grows in application areas such as multimedia, medical imaging, molecular biology, computer aided engineering, marketing, procurement and controlling. In particular, the task of finding similar shapes in 2-D and 3-D becomes more and more important. Based on the shape of a geometric object, similar objects have to be retrieved (similarity search), and clusters of similar objects have to be detected (classification).

A widely used class of similarity models is based on the paradigm of feature vectors.

An example of this paradigm can be described as follows: The shape of a 3-dimensional object is described by a set of 3-dimensional points, aligned onto a regular grid. Thus, an object o is regarded as an element of the power set $\wp(\mathbb{R}_3)$, and the volume or the surface of o (depending on the object type) is measured by its cardinality $|o|$. Using a feature transform, any object o is mapped onto a feature vector in an appropriate multidimensional feature space. The similarity of two objects is then defined as the proximity of their feature vectors in the feature space: The closer their feature vectors are located, the more similar the two objects are considered.

The research paper "Effective Similarity Search on Voxelized CAD Objects" by Kriegel H.-P., Kröger P., Mashaël Z., Pfeifle M., Pötke M., and Seidl T., in Proc. 8th Int. Conf. on Database Systems for Advanced Applications (DASFAA), Kyoto, 2003, pp. 27-38, summarizes a number of known approaches in which feature-based similarity models

are used. In particular, this paper discloses a method for determining feature data for an object by determining a partitioning scheme that defines a plurality of cells in the space in which the object is located and determining the feature data for the object on the basis of at least one property, e.g., the volume, of the respective portions of the object
5 that are contained in the plurality of cells. Partitioning schemes based on equidistant shells or regular sectors or combinations thereof are disclosed. The above research paper is herewith incorporated into the present document in its entirety.

The research paper "Rotation Invariant Spherical Harmonic Representation of 3D Shape
10 Descriptors" by Kazhdan M., Funkhouser T., and Rusinkiewicz S. in Proc. 1st Euro-graphics Symposium on Geometry Processing (SGP), Aachen, 2003, pp. 167-175, contains an overview of various known approaches to the problem of evaluating shape similarity.

15 An object of the present invention is to provide a technology for improving the accuracy and/or effectiveness and/or performance and/or usefulness of prior art methods for determining geometric feature data. In a preferred embodiment, the feature data has the property that it improves the accuracy of a subsequent similarity search or classification such that an improved overall accuracy may be achieved and/or the computational effort
20 and amount of storage required to achieve a desired accuracy level may be reduced.

According to the present invention, the above object is achieved at least in part by a method according to claim 1, a method according to claim 5, a use according to claim 14, a use according to claim 15, a computer program product according to claim 16, and
25 an apparatus according to claim 17. The dependent claims define preferred embodiments of the invention.

A first aspect of the invention is based on the idea to use a partitioning scheme that defines a plurality of cells such that at least two of these cells overlap each other at least
30 in part. Such a partitioning scheme will also be called a "redundant partitioning scheme" in the present document. The redundancy in itself requires additional computational effort. However, experiments have resulted in the surprising finding that this effect is

overcompensated by the increase in accuracy of the obtained feature data so that it becomes possible to use much coarser partitioning schemes than those which would be necessary according to the prior art. All in all, the total computational effort and storage requirements are significantly reduced by the seemingly wasteful use of redundant
5 partitioning schemes.

According to a second aspect of the present invention, a partitioning scheme is used that defines a plurality of cells, wherein at least some of the boundaries of these cells delimit a plurality of regions in the space in which the object is located such that the respective
10 portions of the object that are contained in the plurality of regions are approximately equal to each other with respect to a predetermined measurement metric. Partitioning schemes that define cells that may be grouped into such regions are called "proportional partitioning schemes" in the present document. Again, experiments have shown that the use of a proportional partitioning scheme leads to higher overall accuracy and/or makes
15 it possible to select coarser partitioning schemes than would otherwise be necessary.

The partitioning scheme may define, in preferred embodiments of the invention, many overlapping cells. For example, at least 50 % or at least 90 % of all cells defined by the partitioning scheme may overlap other cells partially or completely. In some
20 embodiments, the plurality of cells may contain at least two groups of cells that partition one and the same region in the space in which the object is located in different ways. In other words, the respective unions of all cells in each of these groups of cells coincide, and each cell in one group overlaps at least in part with at least one cell of each other group.

25 In some embodiments of the invention, the cells defined by the partitioning scheme may comprise a group of nested cells. Each overlapping of cells in this group is a complete overlapping. The partitioning scheme may or may not define additional cells that do not belong into this group of nested cells. The cells of the group of nested cells preferably
30 form a sequence in which the k -dimensional volume of the respective portions of the object that are contained in the cells of the group of nested cells increases in an approximately or exactly regular manner. In other words, the first cell in the group of

nested cells may contain one volume unit of the object, the second cell may contain approximately one additional volume unit, the third cell a further additional volume unit, and so on. Other embodiments may use a partitioning scheme that does not specify any complete overlapping – i.e., nesting – of any cells, but only partial overlappings.

5

Although the use of a partitioning scheme that is either redundant or proportional already confers substantial advantages, it is especially preferred to use a partitioning scheme that is both redundant and proportional. Experiments have shown that this combination achieves unexpected synergistic benefits that go beyond the mere sum of the benefits of only redundant and only proportional partitioning schemes. In some embodiments, the redundant and proportional aspects are combined in a way such that at least one of the proportional regions contains at least two partially or fully overlapping cells.

10

15 In some embodiments the proportional regions are disjoint with respect to each other, while in other embodiments these regions overlap at least in part. The regions do not necessarily need to cover the complete space in which the object is located. In some embodiments there are additional cells that are not part of any of the proportional regions, while in other embodiments all cells that are defined by the partitioning scheme belong to at least one of the regions.

20

It is preferred that the measurement metric according to which the respective portions of the object contained in the regions are required to be approximately equal is the k -dimensional volume of the respective portions of the object. In the three-dimensional case, this volume would be the "usual" spatial volume of the respective object portions, while the two-dimensional volume would actually be the area taken in by the respective object portions. Other metrics may be used in other embodiments, for example the surface area of a three-dimensional object portion.

25

30 According to the second aspect of the present invention, the proportional regions are delimited by the boundaries of the cells defined by the partitioning scheme. In preferred embodiments, this means that each region corresponds to the union and/or difference

and/or intersection of at least two cells or to exactly one cell. Preferably, each region may correspond to a single cell or to a group of cells or to the difference of a first cell or group of cells minus a second cell or group of cells.

- 5 In general, the cells and/or regions may have any suitable shape, but a regular shape is often advantageous. Preferably at least some of the cells and/or regions or all of the cells and/or regions have one of the following shapes: k -dimensional spheres, k -dimensional shells, sectors of k -dimensional spheres, and sectors of k -dimensional shells in the space in which the object is located.

10

The present invention comprises the step of determining the feature data for the object on the basis of at least one property of the respective portions of the objects that are contained in the partitioning scheme cells. Several ways of accomplishing this step are known as such and may also be used in connection with an implementation of the
15 present invention. For example, the feature data for the object may be determined on the basis of the k -dimensional volume of each respective portion of the object contained in each cell of the plurality of cells and/or on the basis of data defining the k principal axes of each respective portion of the object contained in each cell of the plurality of cells.

- 20 The feature data that is obtained by the present invention may, in some embodiments, be a feature vector. This feature data may be used in a variety of ways, which are also known as such. For example, the feature data may be used for performing a similarity search or a similarity classification of a plurality of objects.

- 25 The computer program product of the present invention comprises program instructions that implement the inventive methods. The computer program product may, for example, be a material data carrier like, e.g., a semiconductor memory or a computer disk or a CD-ROM. However, the computer program product may also be an immaterial data carrier like, e.g., a signal transmitted in a computer network. The apparatus of the
30 present invention may be a common personal computer or a workstation or a mainframe computer or a computer network programmed to implement the inventive methods. Preferred embodiments of the computer program product and/or the apparatus comprise

features that correspond to the features mentioned above and/or in the dependent method claims.

Further features, objects and advantages of the present invention will be apparent from
5 the following detailed description of several sample embodiments. Reference is made to the drawings, in which:

Fig. 1 shows an example of an object and the corresponding minimum bounding sphere,

10 Fig. 2 shows an example of a disjoint and equidistant partitioning scheme according to the prior art,

Fig. 3 shows an example of a disjoint and proportional partitioning scheme according to a first embodiment of the present invention,

15 Fig. 4 shows a first example of a redundant and equidistant partitioning scheme according to a second embodiment of the present invention,

Fig. 5 shows a second example of a redundant and equidistant partitioning scheme
20 according to a third embodiment of the present invention,

Fig. 6 shows a first example of a redundant and proportional partitioning scheme according to a fourth embodiment of the present invention,

25 Fig. 7 shows a second example of a redundant and proportional partitioning scheme according to a fifth embodiment of the present invention,

Fig. 8 shows a precision-recall plot comparing the prior art partitioning scheme of Fig. 2 and the partitioning scheme of Fig. 6, and

30 Fig. 9 shows a diagram comparing the total runtime for a classification using the prior art partitioning scheme of Fig. 2 and the partitioning scheme of Fig. 6 on protein data.

The present invention is generally used to obtain feature data that represents information about the shape of an object, the object being located in a k -dimensional space. In the sample embodiments that are described in the following, an object o will be specified by a set of k -dimensional points, aligned onto a regular grid. Thus, the object o can be regarded as an element of the power set $\wp(\mathbb{R}_k)$. We suppose that a predetermined set $O \subset \wp(\mathbb{R}_k)$, namely the domain of k -dimensional objects, has been defined. The volume or the surface of o (depending on the object type) is measured by its cardinality $|o|$.

The feature data obtained in the present sample embodiments is called a "feature vector". Formally, the present sample embodiments implement a so-called feature transform or feature extractor $\phi : O \rightarrow \mathbb{R}_h$, which maps any object o of the object domain O onto a corresponding feature vector in an appropriate h -dimensional feature space.

The intended use of the feature data is for performing similarity searches or similarity classifications. The similarity of two objects may be defined as the proximity of their feature vectors in the feature space: The closer their feature vectors are located, the more similar the two objects are considered. More formally, let $\delta : \mathbb{R}_h \times \mathbb{R}_h \rightarrow \mathbb{R}$ be a distance function between two h -dimensional feature vectors. The distance function δ may, for example, be the Manhattan distance or the Euclidian distance. The feature-based object similarity $\sigma : O \times O \rightarrow \mathbb{R}$ of two objects $o_1, o_2 \in O$ is then defined by $\sigma(o_1, o_2) = \delta(\phi(o_1), \phi(o_2))$. In alternative embodiments, other measures of object similarity can be used that take into account possible rotations or reflections or translations of the objects; reference is made to section 3.3. of the already cited research paper "Effective Similarity Search on Voxelized CAD Objects" in this respect.

In the present sample embodiments, the calculation of a feature vector for an object o is based on a partitioning scheme that defines a plurality of cells in the k -dimensional space in which the object o is located. A variety of domains can be chosen for this partitioning scheme. In the present sample embodiments, the minimum bounding sphere $bs(o)$ of the object o is used as the domain for the partitioning scheme. This is shown in

Fig. 1. More formally, the *minimum bounding sphere* $bs(o) \subset \mathbb{R}_k$ of an object $o \in O$ is the smallest k -dimensional sphere around the center of mass c of o , such that o is completely covered by $bs(o)$. Other domains for the partitioning scheme may be used in alternative embodiments of the present invention.

5

According to the present sample embodiments, a partitioning scheme defines a plurality of spatial cells p_i for an object o such that the union of these cells p_i completely fills the domain for this partitioning scheme, i.e., in the present case, the minimum bounding sphere $bs(o)$. More formally, let $O \subset \wp(\mathbb{R}_k)$ be a domain of k -dimensional objects, and
10 let $P \subset \wp(\mathbb{R}_k)$ be a domain of k -dimensional cells. Then a *partitioning scheme* $\pi: O \rightarrow P_d$ defines for a given object $o \in O$ and its minimum bounding sphere $bs(o)$ a sequence $\pi(o) = (p_1, \dots, p_d)$ of d spatial cells, where $\bigcup_{i=1}^d p_i = bs(o)$. It should be noted that the cells p_i defined by the partitioning scheme π do not necessarily have to be disjoint.

15

The feature data or feature vector for the object o is determined on the basis of at least one property of the respective portions of the object o that are contained in each of the cells p_i according to the partitioning scheme π . For formalizing this concept, an *aggregation* $\alpha: O \times P \rightarrow \mathbb{R}_a$ is introduced, which maps all points of $o \in O$ that are
20 contained in a given cell $p \in P$ onto an a -dimensional vector $\alpha(o, p)$. The feature extractor $\phi: O \rightarrow \mathbb{R}_h$ of the present sample embodiments then has the property that it can be expressed as the concatenation of the results of the aggregation function α applied to the object o and the individual cells p_i of the partitioning scheme. More formally, the feature extractor $\phi: O \rightarrow \mathbb{R}_h$ of the present sample embodiments has the
25 property that a partitioning π and an aggregation α exist such that ϕ can be expressed as $\phi(o) = (\alpha(o, p_1), \dots, \alpha(o, p_d))$, where $\pi(o) = (p_1, \dots, p_d)$ and $h = d \cdot a$. We call such a feature extractor ϕ a *partitioning scheme based feature extractor*.

Fig. 2 shows a partitioning scheme as known in the prior art with three cells ($d = 3$).
30 This partitioning scheme has the properties that (1) all cells p_i are *disjoint*, and (2) the boundaries of the cells p_i are *equidistant*. The first cell p_1 has the shape of a k -dimensional sphere (i.e., a circle in the case $k = 2$ and a spatial sphere in the case

$k = 3$), and the second and third cells p_2, p_3 each have the shape of a k -dimensional shell around the center c of the minimum bounding sphere $bs(o)$. The partitioning scheme of Fig. 2 is called *DE* for *d*isjoint and *e*quidistant.

5 Fig. 3 depicts a partitioning scheme according to a first sample embodiment of the present invention with three cells ($d = 3$). Generally, all partitioning schemes of the present invention are especially suitable for heterogeneous object databases. The partitioning scheme of Fig. 3 is a so-called *proportional partitioning scheme*. In the proportional partitioning schemes of the sample embodiments described herein, the
10 boundaries of the cells or some of these boundaries delimit a number of regions in the space such that the object volume captured in each region is at least approximately constant. Thus, the cell and region boundaries adapt to the individual shape of each object.

15 In the sample embodiment of Fig. 3, each cell p_1, p_2, p_3 corresponds exactly to one of these proportional regions, which are denoted r_1, r_2, r_3 . More formally, each of the regions $r_i, 1 \leq i \leq 3$, has the property that the fraction of the object o contained in the region r_i has a constant volume, i.e. $|o \cap r_i| = \frac{|o|}{d'}$ for $d' = d = 3$ and $r_i = p_i$.

20 The proportional partitioning scheme of Fig. 3 is called *DP* for *d*isjoint and *p*roportional. If the prior art partitioning scheme of Fig. 2 is referred to as a shape histogram, then the approach of Fig. 3 may be called a *shape quantile*, where a *quantile* is determined by the number d of partitioning cells defined by the partitioning scheme.

25 Fig. 4 shows a further sample embodiment of the present invention, namely a so-called redundant partitioning scheme with three cells ($d = 3$). Experiments have demonstrated that the use of redundancy – i.e., overlapping cells – often increases the quality and usefulness of the similarity data, especially for complex objects. It is believed that the whole object shape is preserved much better by not splitting the object into disjoint
30 cells. In the present sample embodiments, the concept of a redundant partitioning scheme $\pi: O \rightarrow P_d$ with $\pi(o) = (p_1, \dots, p_d)$ can formally be expressed by the property

that cells p_i, p_j exist for $i \neq j$ and $1 \leq i, j \leq d$, which share a non-empty spatial region, i.e., $p_i \cap p_j \neq \emptyset$.

In the sample embodiment of Fig. 4, the cells p_i form a single group gn of nested cells.

- 5 In other words, the smallest cell p_1 is fully contained in the cell p_2 , and the cell p_2 in turn is fully contained in the largest cell p_3 . The cells p_1 to p_3 therefore constitute a fully ordered sequence with respect to the "is contained in" relation. Furthermore, the boundaries of the cells p_i are equidistant.

- 10 Fig. 5 shows a further sample embodiment of a redundant and equidistant partitioning scheme with seventeen cells ($d = 17$). This scheme is derived from the prior art partitioning scheme of Fig. 2 by subdividing the cells p_2 and p_3 of Fig. 2. More specifically, the second cell p_2 of Fig. 2 has been subdivided into a first group gi_1 of inner cells p_2 to p_5 and a second group gi_2 of inner cells p_6 to p_9 . The cells contained
15 in each of these groups gi_1, gi_2 are disjoint within the respective group gi_1, gi_2 . However, the groups gi_1, gi_2 are shifted with respect to each other such that each cell in one of the groups gi_1, gi_2 overlaps with two cells of the other group gi_1, gi_2 . Likewise, the third cell p_3 of Fig. 2 has been subdivided into a first group go_1 of outer cells p_{10} to p_{13} and a second group go_2 of outer cells p_{14} to p_{17} . Each of the cells p_2 to p_{17} has
20 the shape of a sector of a k -dimensional shell in the minimum bounding sphere $bs(o)$.

The examples of redundant and equidistant partitioning schemes of Fig. 4 and Fig. 5 are called $RE_1(o)$ and $RE_2(o)$, respectively.

- 25 Experiments have shown that the benefits are especially large if proportional and redundant partitioning is combined. A combined *redundant* and *proportional* partitioning scheme is called RP . Fig. 6 and Fig. 7 show two sample embodiments of RP -partitioning.

- 30 The scheme $RP_1(o)$ of Fig. 6 defines three cells ($d = 3$). This scheme is similar to the scheme $RE_1(o)$ of Fig. 4 in that it defines a group gn of three nested cells p_1, p_2, p_3 . However, in contrast to the scheme $RE_1(o)$ of Fig. 4, the boundaries of the cells p_1, p_2 ,

p_3 further define three proportional regions r_1, r_2, r_3 such that $|o \cap r_i| = \frac{|o|}{d'}$ for $d' = 3$ holds. The first region r_1 is identical to the first cell p_1 . The second region r_2 is delimited by the boundaries of the first and second cells p_1 and p_2 . The third region r_3 is delimited by the boundaries of the second and third cells p_2 and p_3 . In other words, the second region r_2 is the difference of p_2 minus p_1 , and the third region r_3 is the difference of p_3 minus p_2 .

It should further be noted that, in the example of Fig. 6, the volume of the respective portions of the object o in the cells p_1 to p_3 increases in a regular way, i.e., by $1/d$ of the total volume of the object o for each cell. In the present example with three cells, the first cell p_1 thus contains about $1/3$ of the total volume of the object o , the second cell p_2 about $2/3$, and the third cell p_3 the full volume.

The scheme $RP_2(o)$ of Fig. 7 defines seventeen cells ($d = 17$). This scheme is similar to the scheme $RE_2(o)$ of Fig. 5 in that it defines two redundant groups gi_1 and gi_2 of inner cells and two redundant groups go_1 and go_2 of outer cells. However, in contrast to the scheme $RE_2(o)$ of Fig. 5, the boundaries of the cells of $RP_2(o)$ further define three proportional regions r_1, r_2, r_3 such that $|o \cap r_i| = \frac{|o|}{d'}$ for $d' = 3$ holds; d' is the number of regions. The first region r_1 is identical to the first cell p_1 . The second region r_2 is delimited by the curved boundaries of the cells p_2 to p_9 . The third region r_3 is delimited by the curved boundaries of the cells p_{10} to p_{17} . In other words, the second region r_2 is the union of p_2 to p_9 , and the third region r_3 is the union of p_{10} to p_{17} .

As mentioned above, the methods of the present sample embodiments use a partitioning scheme as shown in one of Fig. 3 to Fig. 7 in order to determine a feature vector for the object o on the basis of an aggregation $\alpha : O \times P \rightarrow \mathbb{R}_\alpha$. Suitable aggregation functions are known as such. For example, an aggregation $\alpha_1 : O \times P \rightarrow \mathbb{R}_1$ may be used that calculates the normalized volume of the portion of the object o that is contained within the respective cell p . Alternatively, an aggregation $\alpha_2 : O \times P \rightarrow \mathbb{R}_k$ may be used that defines the variance along the k principal axes of the portion of the object o that is contained within the respective cell p . The calculation of aggregation α_2 for an object o

and a cell p may comprise determining k eigen values that correspond to k eigen vectors spanning the minimum ellipsoid that bounds the portion of the object o contained within the cell p , then sorting the k eigen values, and finally outputting the sorted k eigen values as the result $\alpha_2(o,p)$. The calculations necessary to implement aggregations α_1 and α_2 are described in more detail in sections 3.4.1 and 3.4.3 of the research paper "Effective Similarity Search on Voxelized CAD Objects", which has been cited above. These sections are incorporated herewith into the present document by reference.

In the above sample embodiments, the feature vector $\phi(o)$ for a given object o is simply the concatenation of all results obtained by applying the aggregation α to all cells p defined by the corresponding partitioning scheme. In other embodiments, further normalization or other additional processing steps may be performed.

All in all, the resulting similarity measure can be used for classifying large collections of objects according to their geometrical features, or for performing database searches for similar objects, or for other tasks in which the geometric similarity of objects must be evaluated.

In order to assess the merits of the present invention, the effectiveness of the presently proposed partitioning approaches have been compared with one of the best prior art techniques, which is based on a DE partitioning with a spherical harmonic value aggregation function, as proposed in the research paper "Rotation Invariant Spherical Harmonic Representation of 3D Shape Descriptors", which has been cited above. Very encouraging results have been obtained. For example, Fig. 8 shows the results for the prior art DE partitioning and the present RP_I partitioning on a protein database. At a recall of 50%, the RP_I -based method shows a precision of 42%, as opposed to a precision of 26% for the DE -based method. At a recall of 80%, RP_I delivers nearly twice the precision than DE . Similar results have been obtained on CAD and on web data.

Fig. 9 shows performance results that have been obtained in the same configuration as above. It is apparent that RP_I runs about 10 times faster than DE . Thus, RP_I does not

only yield a much higher effectiveness than *DE*, but also has a dramatically lower runtime cost. The slower performance of *DE* is due to the fact that it requires a much more fine-grained partitioning scheme in order to deliver good results. Thus, the generated feature vectors for *DE* are much longer and more expensive to be evaluated
5 by the distance function.

It is apparent that the present invention can be used for improving the accuracy and effectiveness of similarity based search and/or classification methods. The particulars contained in the above description of sample embodiments should not be construed as
10 limitations of the scope of the invention, but rather as exemplifications of preferred embodiments thereof. Many other variations are possible and will be readily apparent to persons skilled in the art. Accordingly, the scope of the invention should be determined not by the embodiments illustrated, but by the appended claims and their legal
15 equivalents.

08. März 2004

Claims

1. A method for determining feature data that represents information about the shape of an object (o), the object (o) being located in a k -dimensional space, the method comprising the steps of:
- determining a partitioning scheme (RE, RP) that defines a plurality of cells (p) in the space in which the object (o) is located such that at least some of the cells (p) each contain a respective portion of the object (o), and
 - determining the feature data for the object (o) on the basis of at least one property of the respective portions of the object (o) that are contained in the plurality of cells (p),
- the method being characterized in that
- at least two of the plurality of cells (p) overlap each other at least in part.
2. The method of claim 1, characterized in that the plurality of cells (p) comprises at least a first and a second group of cells ($gi_1, gi_2; go_1, go_2$) such that the union of the cells in the first group of cells ($gi_1; go_1$) coincides with the union of the cells in the second group of cells ($gi_2; go_2$), wherein each cell of the first group of cells ($gi_1; go_1$) overlaps at least in part with at least one respective cell of the second group of cells ($gi_2; go_2$).
3. The method of claim 1 or claim 2, characterized in that the plurality of cells (p) comprises at least a group of nested cells (gn), wherein all cells of the group of nested cells (gn) are nested within each other.
4. The method of claim 3, characterized in that the cells of the group of nested cells (gn) form a sequence in which the k -dimensional volume of the respective portions of the object (o) that are contained in the cells of the group of nested cells (gn) increases in an at least approximately regular manner.

5. A method for determining feature data that represents information about the shape of an object (o), the object (o) being located in a k -dimensional space, the method comprising the steps of:

- determining a partitioning scheme (DP, RP) that defines a plurality of cells (p) in the space in which the object (o) is located such that at least some of the cells (p) each contain a respective portion of the object (o), and
- determining the feature data for the object (o) on the basis of at least one property of the respective portions of the object (o) that are contained in the plurality of cells (p),

10 the method being characterized in that

- at least some of the boundaries of the cells (p) delimit a plurality of regions (r) in the space in which the object (o) is located such that the respective portions of the object (o) that are contained in the plurality of regions (r) are approximately equal to each other with respect to a predetermined measurement metric.

15

6. The method of claim 5 and one of claims 1 to 4.

7. The method of claim 5 or claim 6, characterized in that at least one region (r) of the plurality of regions (r) contains at least two cells (p) of the plurality of cells (p) that overlap each other at least in part.

20

8. The method of one of claims 5 to 7, characterized in that all regions (r) of the plurality of regions (r) are disjoint with respect to each other.

9. The method of one of claims 5 to 8, characterized in that the measurement metric, for each region (r) of the plurality of regions (r), is the k -dimensional volume of the respective portion of the object (o) contained in this region (r).

25

10. The method of one of claims 5 to 9, characterized in that each region (r) of the plurality of regions (r) corresponds to the union and/or difference and/or intersection of at least two cells (p) of the plurality of cells (p) or to exactly one cell (p) of the plurality of cells (p).

30

11. The method of one of claims 5 to 10, characterized in that at least some of the regions (r) of the plurality of regions (r) represent k -dimensional spheres and/or k -dimensional shells and/or sectors of k -dimensional spheres and/or sectors of k -dimensional shells in the space in which the object (o) is located.
12. The method of one of claims 1 to 11, characterized in that at least some of the cells (p) defined by the partitioning scheme (DP , RE , RP) represent k -dimensional spheres and/or k -dimensional shells and/or sectors of k -dimensional spheres and/or sectors of k -dimensional shells in the space in which the object (o) is located.
13. The method of one of claims 1 to 12, characterized in that the feature data for the object (o) is determined on the basis of the k -dimensional volume of each respective portion of the object (o) contained in each cell (p) of the plurality of cells (p) and/or on the basis of data defining the k principal axes of each respective portion of the object (o) contained in each cell (p) of the plurality of cells (p).
14. Use of a method according to one of claims 1 to 13 for performing a similarity search between a first object and a set of second objects, wherein feature data for the first object and for each of the set of second objects is determined according to the method according to one of claims 1 to 13, and wherein the similarity search is performed on the basis of a comparison of the determined feature data.
15. Use of a method according to one of claims 1 to 13 for performing a similarity classification of a set of objects, wherein feature data for each object of the set of objects is determined according to the method according to one of claims 1 to 13, and wherein the objects of the set of objects are grouped according to their respective similarities on the basis of a classification of the determined feature data.
16. Computer program product comprising program instructions for execution by at least one processor, wherein the program instructions cause the at least one processor to perform or use a method according to one of claims 1 to 15.

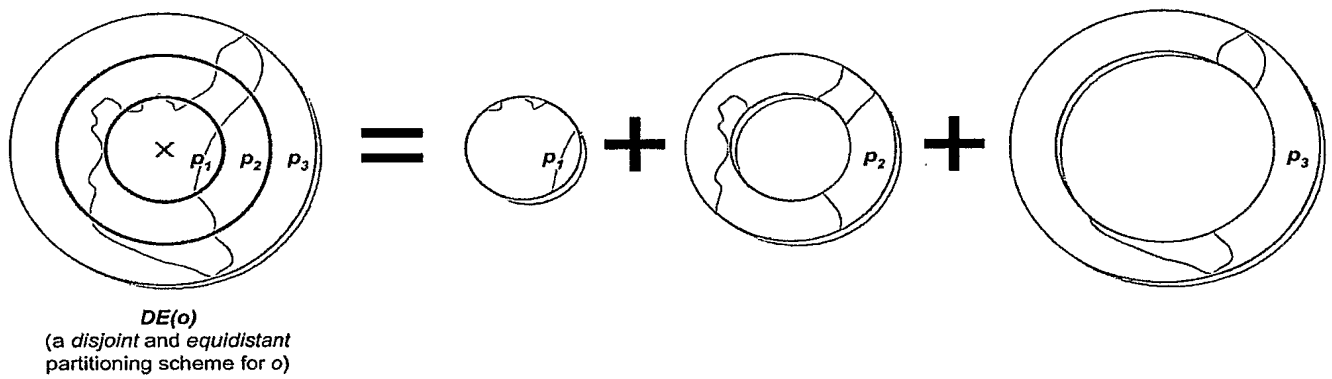
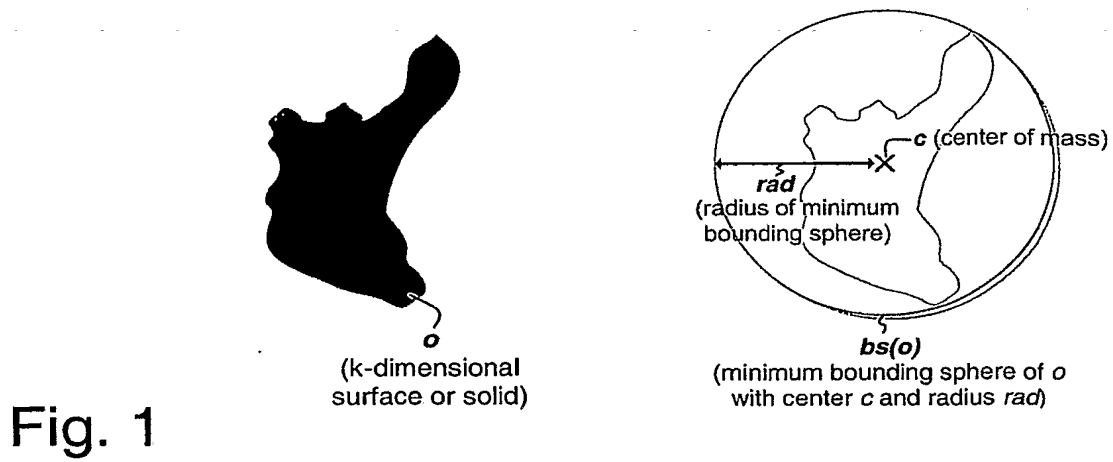
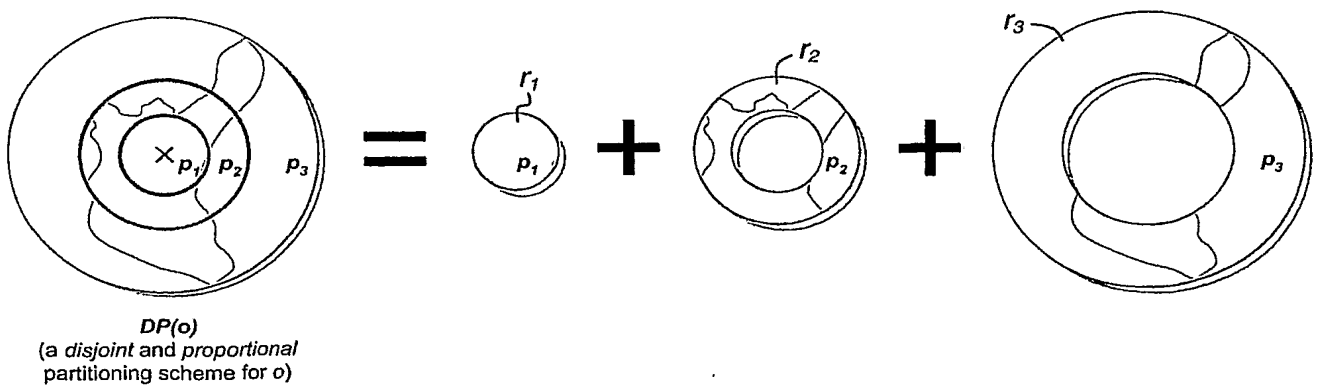
17. Apparatus comprising at least one processor, wherein the apparatus is adapted for performing or using a method according to one of claims 1 to 15.

08. März 2004

Abstract

The invention concerns a method for determining feature data that represents information about the shape of an object. A partitioning scheme (*RP*) is determined that
5 defines a plurality of cells (*p*) in the space in which the object is located such that at least some of the cells (*p*) each contain a respective portion of the object, and the feature data is determined for the object on the basis of at least one property of the respective portions of the object that are contained in the plurality of cells (*p*). According to a first aspect of the invention, at least two of the plurality of cells (*p*) overlap each other at
10 least in part, and according to a second aspect of the invention, at least some of the boundaries of the cells (*p*) delimit a plurality of regions (*r*) in the space in which the object is located such that the respective portions of the object that are contained in the plurality of regions (*r*) are approximately equal to each other with respect to a predetermined measurement metric. The method may be used for performing a
15 similarity search or for performing a similarity classification. A computer program product and an apparatus comprise corresponding features. The invention provides a technology for improving the accuracy and/or effectiveness and/or performance and/or usefulness of prior art methods for determining geometric feature data.

20 (Fig. 7)

**Fig. 2 (Prior Art)****Fig. 3**

2/4

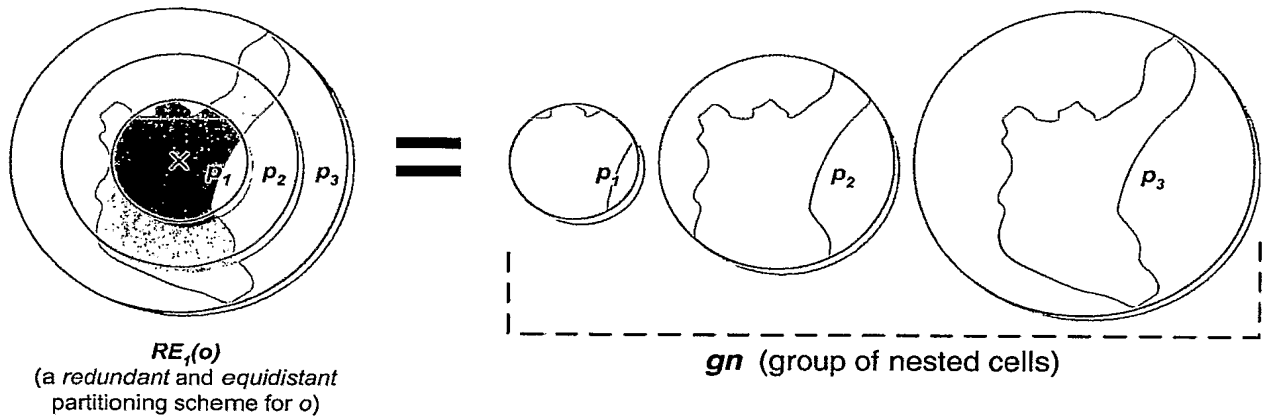


Fig. 4

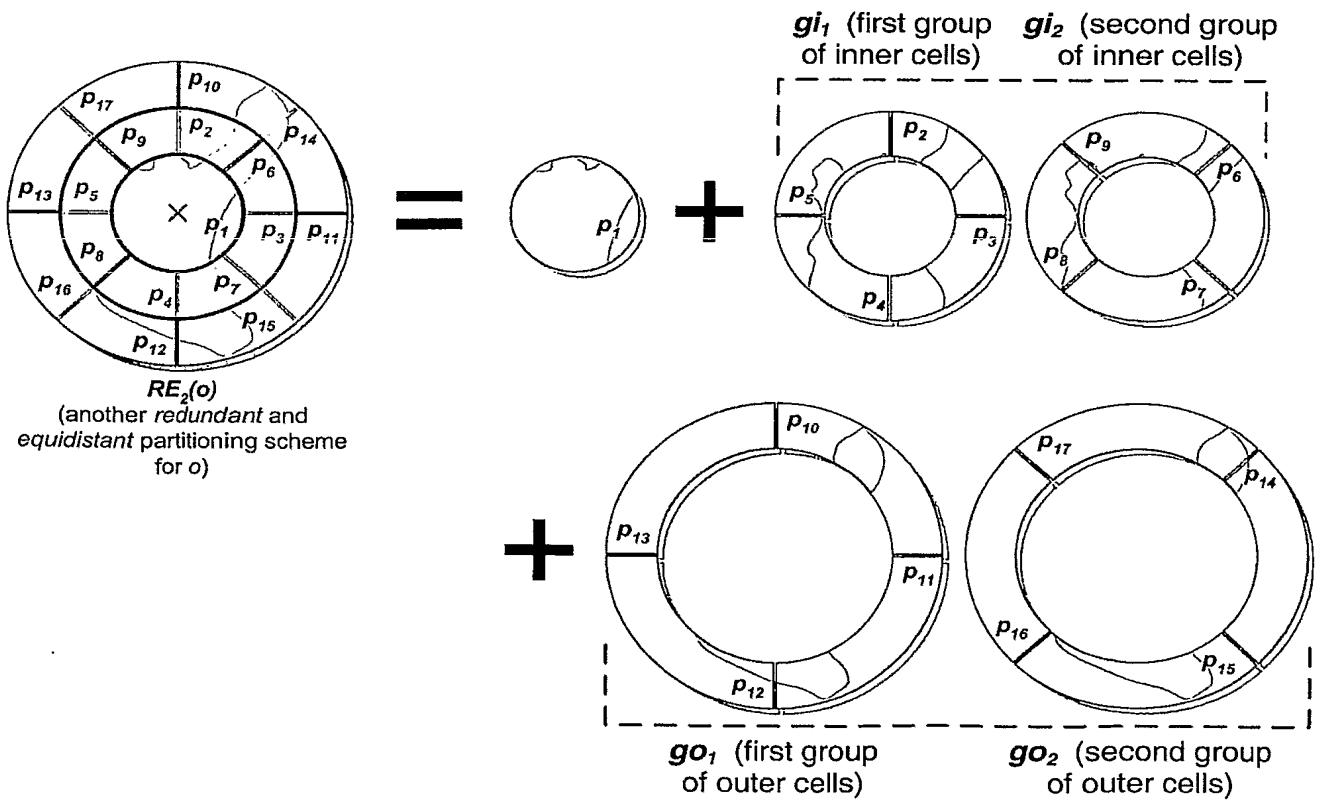


Fig. 5

3/4

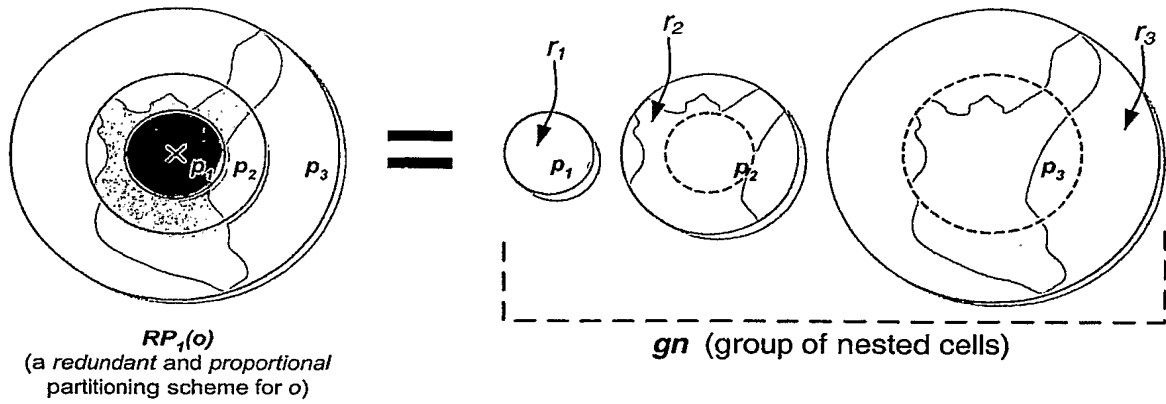


Fig. 6

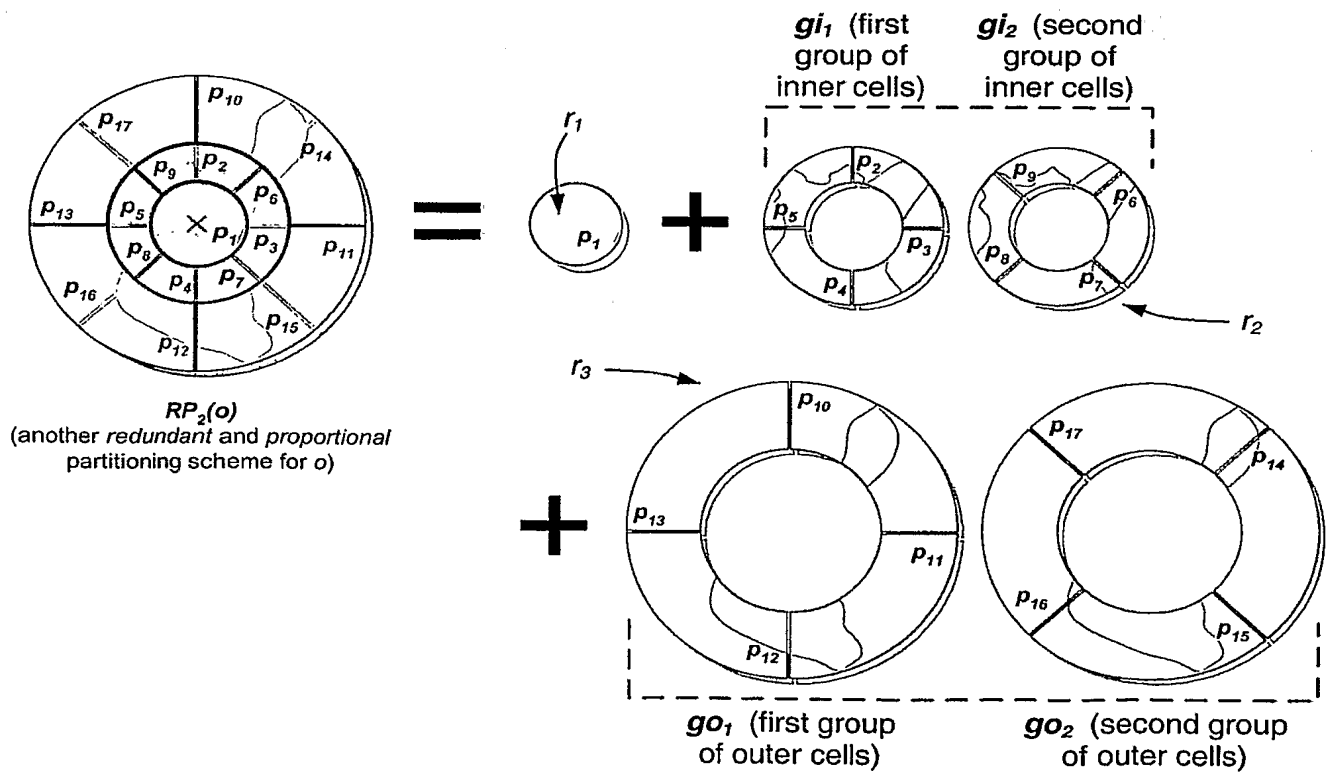


Fig. 7

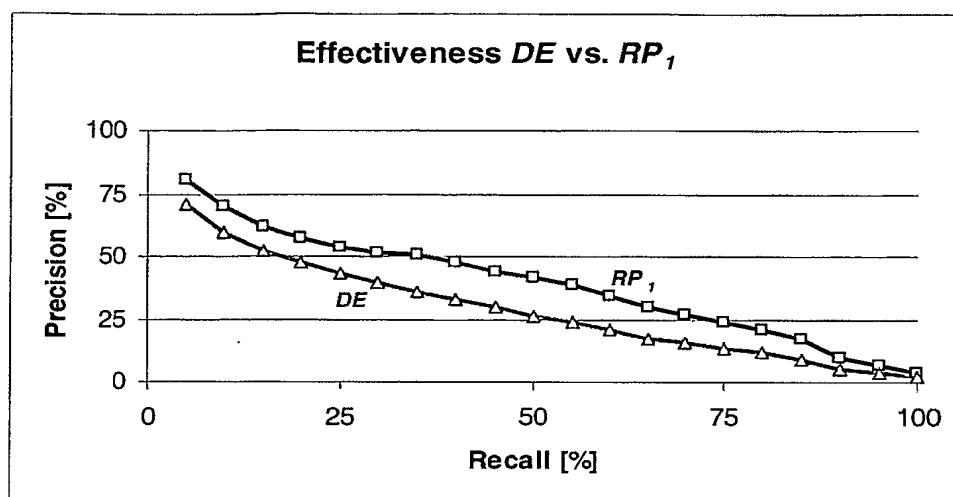


Fig. 8

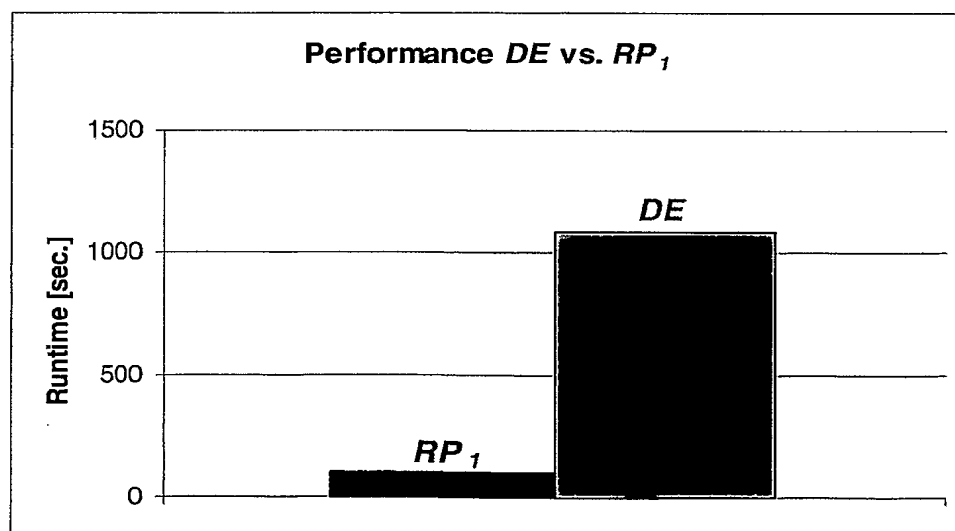


Fig. 9